

United States Patent [19]

Vanderbei

[11] Patent Number: 4,744,026

[45] Date of Patent: May 10, 1988

[54] METHODS AND APPARATUS FOR
EFFICIENT RESOURCE ALLOCATION

[75] Inventor: Robert J. Vanderbei, Red Bank, N.J.

[73] Assignee: American Telephone and Telegraph
Company, AT&T Bell Laboratories,
Murray Hill, N.J.

[21] Appl. No.: 851,120

[22] Filed: Apr. 11, 1986

[51] Int. Cl. 4 G06F 15/20; H04Q 3/66;
H04M 7/00

[52] U.S. Cl. 364/402; 379/113;
379/221; 340/827

[58] Field of Search 364/402; 379/113, 221;
340/827

[56] References Cited

U.S. PATENT DOCUMENTS

3,591,724	7/1971	Yaku et al.	379/137
4,284,852	8/1981	Szybicki et al.	379/221
4,345,116	8/1982	Ash et al.	379/221
4,669,113	5/1984	Ash et al.	379/221
4,704,724	11/1987	Krishnan et al.	379/221

OTHER PUBLICATIONS

Introduction to Operations Research, F. Hillier and G. Lieberman, 1980, pp. 91-109.

Technical Report No. 648, "An Extension of Karmarkar's Algorithm for Linear Programming Using Dual Variables", M. J. Todd et al., Cornell University, Jan. 1985.

"Efficient Implementation of a Class of Preconditioned Conjugate Gradient Methods", *Siam J. Sci Stat Comput.*, vol. 2, No. 1, S. C. Eisenstat, Mar. 1981.

"Some Computational Experience and a Modification of the Karmarkar Algorithm", ISME Working Paper

85-105, T. M. Cavalier et al., The Pennsylvania State University.

"A Variation on Karmarkar's Algorithm for Solving Linear Programming Problems", Earl R. Barnes, IBM T. J. Watson Research Center.

"On Projected Newton Barrier Methods for Linear Programming and an Equivalence to Karmarkar's Projective Method", Gill et al., Stanford University, Technical Report Sol. 85-11, Jul. 1985.

Primary Examiner—Joseph F. Ruggiero

Assistant Examiner—Charles B. Meyer

Attorney, Agent, or Firm—Robert O. Nimitz; Henry T. Brendzel

[57] ABSTRACT

A method and apparatus for optimizing resource allocations is disclosed which utilizes the Karmarkar algorithm to proceed in the interior of the solution space polytope. At least one allocation variable is assumed to be unconstrained in value. Each successive approximation of the solution point, and the polytope, are normalized such that the solution is at the center of the normalized polytope using a diagonal matrix of the current solution point. The objective function is then projected into the normalized space and the next step is taken in the interior of the polytope, in the direction of steepest-descent of the objective function gradient and of such a magnitude as to remain within the interior of the polytope. The process is repeated until the optimum solution is closely approximated.

The resulting algorithm steps are advantageously applied to the phase of one problem of obtaining a starting point, and to the dual problem, where the free variable assumption produces unexpected computational advantages.

15 Claims, 6 Drawing Sheets

KARMARKAR ALGORITHM

